a moveable member ~~capable of being physically contacted by a user and moved by said user to different positions~~;

an <u>actuator</u>~~motor~~ coupled to ~~said interface device operative~~<u>the moveable member, the motor being configured</u> to output a ~~force such that modulating said force produces a tactile sensation felt by said user when operating said interface device~~<u>haptic feedback, the haptic feedback including a modulating force</u>;

~~local~~<u>a</u> data storage <u>component configured to</u> ~~in which torque data from said host computer can be stored, said~~<u>store</u> torque data ~~used in controlling said force to produce said tactile sensation generated by said interface device~~<u>associated with the haptic feedback, the torque data being provided by a host computer</u>;

<u>a sensor coupled to the moveable member, the sensor being configured to send position information associated with a position of the moveable member; and</u>

a local controller <u>coupled to the data storage component and the actuator, the controller being configured to be</u> in communication with ~~said~~<u>the</u> host computer, ~~via a communication link and in communication with said local data storage and said motor, said host computer running a host software application, said~~<u>the</u> controller <u>being configured to</u> ~~controlling said~~<u>send a control</u> signal to the ~~motor~~<u>actuator, the control signal being based on data values associated with</u> ~~in accordance with requirements of said~~<u>a</u> host software application <u>of the host computer,</u> ~~wherein said controller accesses said~~<u>the</u> haptic feedback <u>being associated with the</u> ~~torque data from said data storage and uses said torque data to influence control of said motor so as to produce said tactile sensation in accordance with said requirements of said host software application~~<u>position information, and the host software application</u>~~; and~~

~~a sensor coupled to said interface device and operative to provide position information related to said different positions of said member, wherein said position information is provided to said controller.~~

20. (Currently amended)     ~~A~~<u>The</u> ~~tactile feedback interface~~ device ~~as recited in~~<u>of</u> claim 19<u>,</u> ~~wherein said~~<u>the motor</u>~~motor~~<u>actuator</u> ~~is~~<u>being</u> a first ~~motor~~<u>actuator, and</u>~~and~~<u>the device</u> further comprising ~~providing~~<u>a</u> second ~~motor~~<u>actuator,</u> ~~in said interface device such that said~~<u>the</u> controller <u>being configured to output the controls</u> ~~a force output by both said~~<u>signal to the first</u>

and second motoractuators, said the first and second motoractuators working in conjunctionconfigured to produce said tactile sensationthe haptic feedback.

21. (Currently amended) A The tactile feedback interface device as recited inof claim 19, wherein multiple torque values are received from said host computer and stored simultaneously in said local memorythe data storage component is configured to receive and store a plurality of torque values from the host computer.

22. (Currently amended) A The tactile feedback interface device as recited inof claim 21, wherein each set of said the torque values describes is associated with a different tactile sensation.

23. (Currently amended) A The tactile feedback interface device as recited inof claim 19, wherein said localthe data storage component is external to said tactilethe controller.

24. (Currently amended) A The tactile feedback interface device as recited inof claim 19, wherein said localthe data storage component is resident on said tactilethe controller.

25. (New) A device, comprising:

a moveable member, the moveable member being configured to provide haptic feedback, based on a plurality of data values associated with processor executable application, the haptic feedback being associated with a plurality of force output profiles, each of the plurality of force output profiles being uniquely associated with a data value from the plurality of data values;

a local data storage component configured to store the plurality of data values;

a sensor coupled to the moveable member, the sensor being configured to send a position signal associated with a position of the moveable member; and

a local controller coupled to the local data storage component and the sensor, the local controller being configured to control the haptic feedback in response to the position information.

26. (New)     The device of claim 25, wherein the moveable member is a knob, the knob having a plurality of step positions.

27. (New)     The device of claim 25, wherein the moveable member is at least a portion of an actuator, the actuator being configured to provide the haptic feedback.

28. (New)     The device of claim 25, wherein the data storage component is external to the local controller.

29. (New)     The device of claim 25, wherein the data storage component is resident on the local controller.

30. (New)     The device of claim 25, wherein the local data storage component is configured to receive data from a remote processor.

31. (New)     A method, comprising:

sending a position signal to a local controller, the position signal being based on at least one of a position and a movement of a moveable member;

receiving a control signal, the control signal being associated with at least one of an input signal from a computer program, torque signal data from a local memory device, and the position signal; and

outputting haptic feedback at the moveable member, the haptic feedback being associated with the control signal.

32. (New)     The method of claim 31, wherein the torque signal is associated with different tactile sensations of the haptic feedback.

33. (New)     The method of claim 31, further comprising:

receiving at the local memory device, data from a host computer, the data including the input signal.

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